What Is Claimed Is:

1. A sensor system on motor vehicles, for locating objects (18) in front of vehicle (10),

wherein at least two sensors (SR, SL), each having a locating depth of at least 50 m, are arranged in such a way on both sides of longitudinal center axis (12) of the vehicle that their locating angular ranges (RR, RL) together cover the entire vehicle width as of a first distance d1, and overlap each other as of a second distance d2.

2. The sensor system as recited in Claim 1,
wherein the first distance d1 is less than 5 m, preferably approximately 3 m.

3. The sensor system as recited in Claim 1 or 2,
wherein the second distance d2 is less than 10 m, preferably approximately 5 m.

4. The sensor system as recited in one of the preceding claims,
wherein the optical axes (AR, AL) of the two sensors (SR, SL) run parallel to the longitudinal center axis (12) of the vehicle (10).

5. The sensor system as recited in one of the preceding claims,
wherein the sensors (SR, SL) have angular resolution.

6. The sensor system as recited in one of the preceding claims,
wherein the locating angular range (RR, RL) of each of the sensors (SR, SL) to each side of the optical axis (AR, AL) of the sensor in question is less than 10°.

7. A method for distance control in motor vehicles comprising at least two sensors (SR, SL) which are arranged in such a way on both sides of the longitudinal center axis (12) of the vehicle (10) that below a distance d2, their locating angular ranges (RR, RL) form a blind spot (16) between themselves, in which method, when an object (18) is detected by only one of the sensors and this object also leaves the locating range of this one sensor, it is decided whether the object has left the locating range the blind spot (16), and in this case the vehicle is decelerated until the object appears again or until the vehicle is brought to a standstill.

8. The method as recited in Claim 7,

wherein the decision as to whether the object has left the locating range and entered

into the blind spot (16) is made on the basis of locating angle data of the sensors (SR,

SL).

9. The method as recited in Claim 8,

wherein for an object which is in the locating angular range of one of the sensors, it is

checked on the basis of the locating angle data of this sensor whether the object is also

in the locating angular range of the other sensor, and if this is the case, but the object

is not located by the other sensor, a fault report is output.